

IN THE CLAIMS:

Set forth below in ascending order, with status identifiers, is a complete listing of all claims currently under examination. Changes to any amended claims are indicated by strikethrough and underlining. This listing also reflects any cancellation and/or addition of claims.

1-5. (Canceled)

6. (Currently amended) An apparatus, comprising:

a deformable member having a first end, a second end, and an intermediate portion, the intermediate portion of the deformable member having a contact side and a non-contact side; and a tendon configured to displace the first end of the deformable member relative to the second end in response to a signal, the contact side of the intermediate portion of the deformable member configured to output provide a haptic sensation, the non-contact side of the intermediate portion being disposed between the contact side of the intermediate portion and the tendon to an underside of a hand.

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7. (Previously presented) The apparatus of claim 6, wherein the deformable member is a leaf spring.

8. (Previously presented) The apparatus of claim 6, wherein the tendon passes through a guide member fixed to one of the first end and the second end of the deformable member.

9. (Previously presented) The apparatus of claim 6, wherein the deformable member is configured to provide a controllable kinesthetic force.

10. (Previously presented) The apparatus of claim 6, wherein the deformable member is configured to provide a tactile sensation.

11-25. (Canceled)

26. (Currently amended) An apparatus, comprising:
an actuator; and
a forcing mechanism coupled to the actuator, the forcing mechanism positionable on a support surface defining a plane, the forcing mechanism including:

a non-contact surface;

a contact surface configured to output provide a haptic sensation ~~to an underside of a hand~~; and

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means for moving the contact surface in a direction having at least one component outside of the plane defined by the support surface in response to the actuator, the means for moving being positioned such that the non-contact surface is disposed between the means for moving and the contact surface.

27. (Previously presented) The apparatus of claim 26, wherein the contact surface is attached to a flexible member.

28. (Previously presented) The apparatus of claim 26, wherein the means for moving includes a tendon attached to an extremity of the contact surface.

29. (Previously presented) The apparatus of claim 26, wherein the means for moving includes a piston.

30. (Previously presented) The apparatus of claim 26, wherein the means for moving includes a threaded rod.

31. (Previously presented) The apparatus of claim 26, wherein the means for moving includes a cam.

32. (Previously presented) The apparatus of claim 26, wherein the means for moving includes a telescoping member.

33. (Previously presented) The apparatus of claim 26, wherein the means for moving includes an inflatable member.

34. (Previously presented) The apparatus of claim 26, wherein the contact surface includes a multi-point contact surface.

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35. (Previously presented) The apparatus of claim 26, further comprising:
means for securing the contact surface to an object able to receive the feedback force.

36. (Previously presented) The apparatus of claim 26, wherein the contact surface includes a contact surface defining an opening to at least partially enclose an object able to receive the feedback force.

37. (Previously presented) The apparatus of claim 36, wherein the means for moving includes a plurality of finger forcing mechanisms.

38. (Currently amended) A method, comprising:
receiving from a computer a signal associated with a user interface associated with the computer;
moving a contact surface of a forcing mechanism in a direction having at least one component outside the plane of a support surface configured to support the forcing mechanism, the moving being associated with the received signal, the contact surface of the forcing mechanism being configured to output provide a haptic sensation, the forcing mechanism including a non-contact surface disposed between the contact surface of the forcing mechanism and an actuator associated with the moving to an underside of a hand; and

transmitting information to the computer from the forcing mechanism regarding the moving of the contact surface of the forcing mechanism.

39. (Previously presented) The method of claim 38, wherein the receiving includes receiving a signal from the computer associated with a placement of an icon within the user interface.

40. (Previously presented) The method of claim 38, wherein the moving is further based on calculations performed by the computer in response to the information transmitted to the computer
